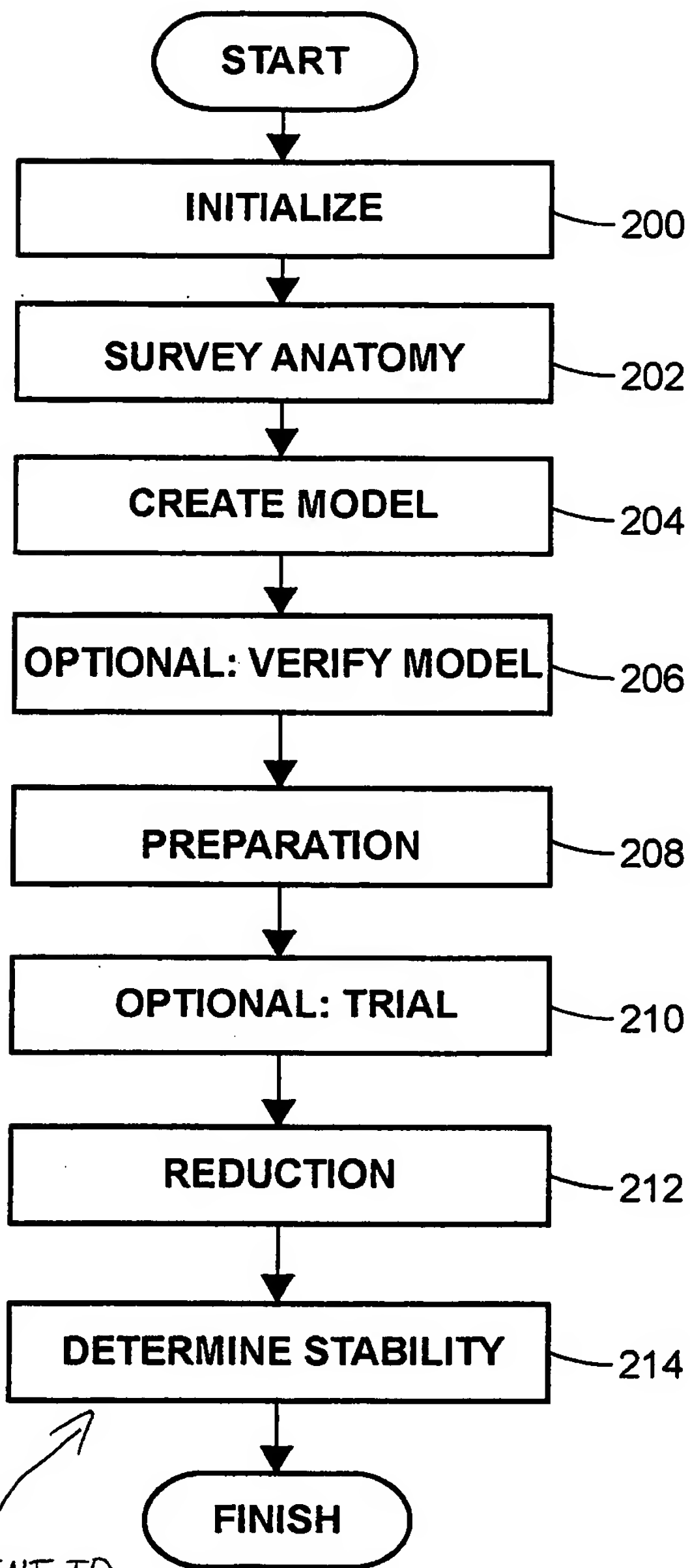


**FIG. 2**



MANIPULATE JOINT TO  
DETERMINE STABILITY  
AND RANGE OF MOTION



**FIG. 2**

